

Fast Micro-mirrors with Large Angle Deflections

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Liquid MEMS

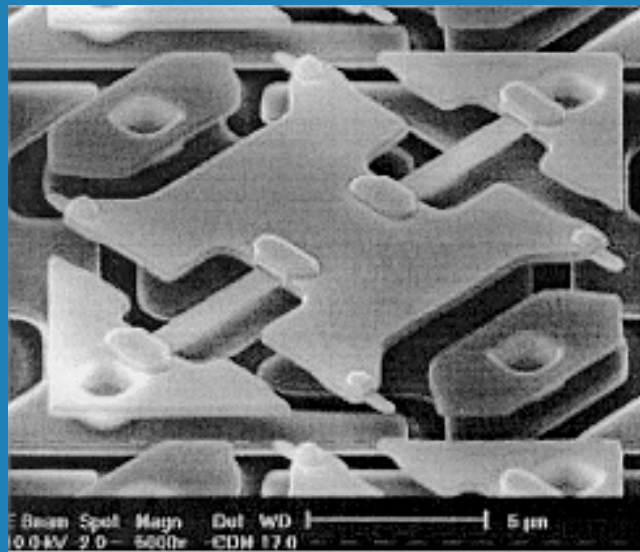
- Liquids don't suffer from stiction.
- Liquids don't suffer from wear and fatigue.
- Electrostatic actuation.
- Thermal actuation.
- Patterned fluid dispensing of 14 pL drops that are 30 μ m in diameter with ~1 μ m accuracy.

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TI Digital Micromirror



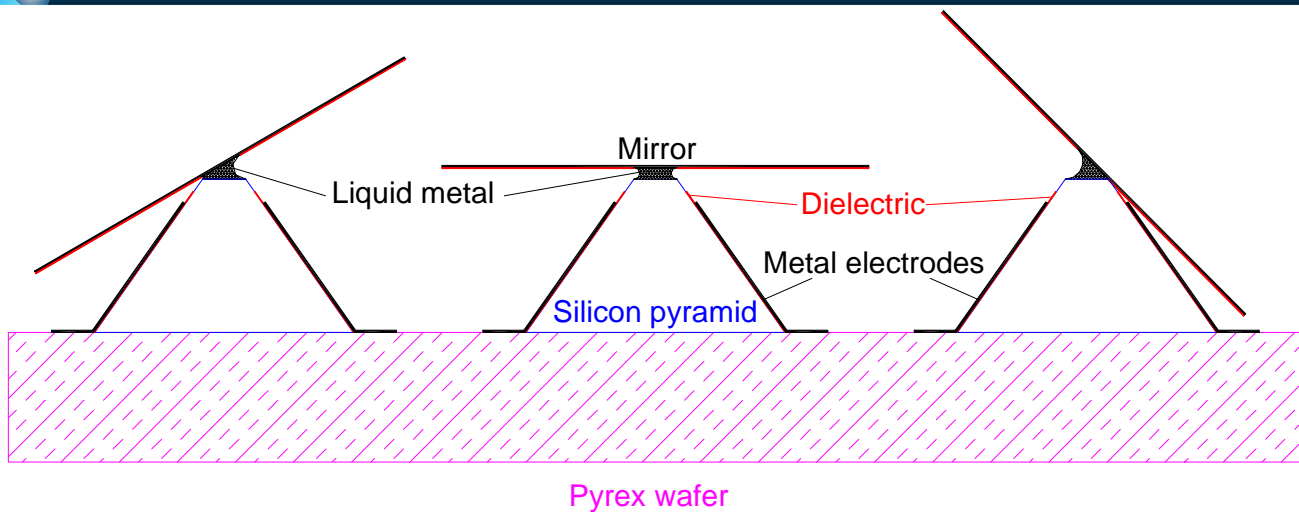
- Constraints on opposite sides of mirror
- Residual stress deflects mirror, useless as analog mirror
- Mechanical weak links are thermal insulators
- Rotates only about one axis

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UIC Micro-mirror

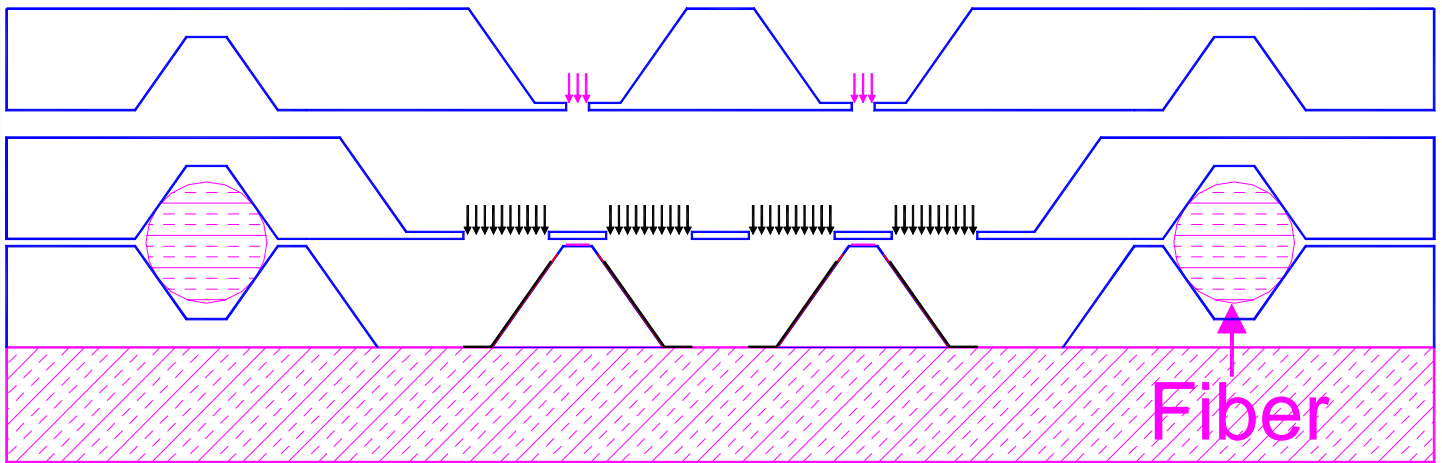


- Conducting liquid drop gives.*
- Restoring force.
 - Electrical connection to moveable plate for electrostatic actuation.
 - Good thermal connection to moveable plate.

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Lithography on Non-planar Substrates



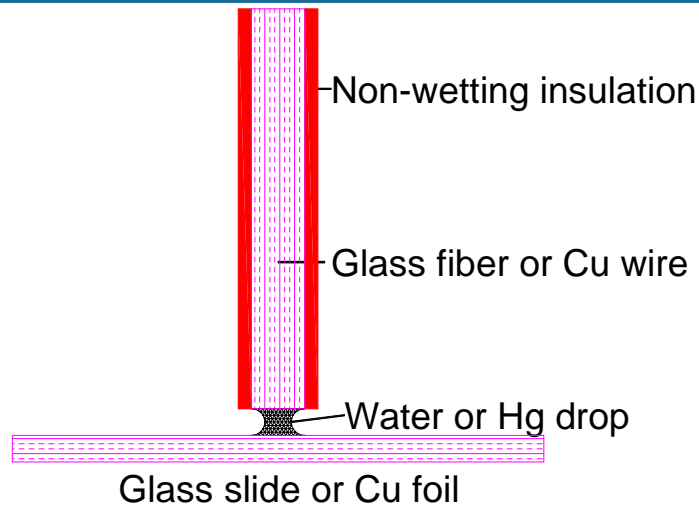
Aligned shadow masks can selectively deposit or etch thin films on non-planar substrates.

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Prototype Micromirror



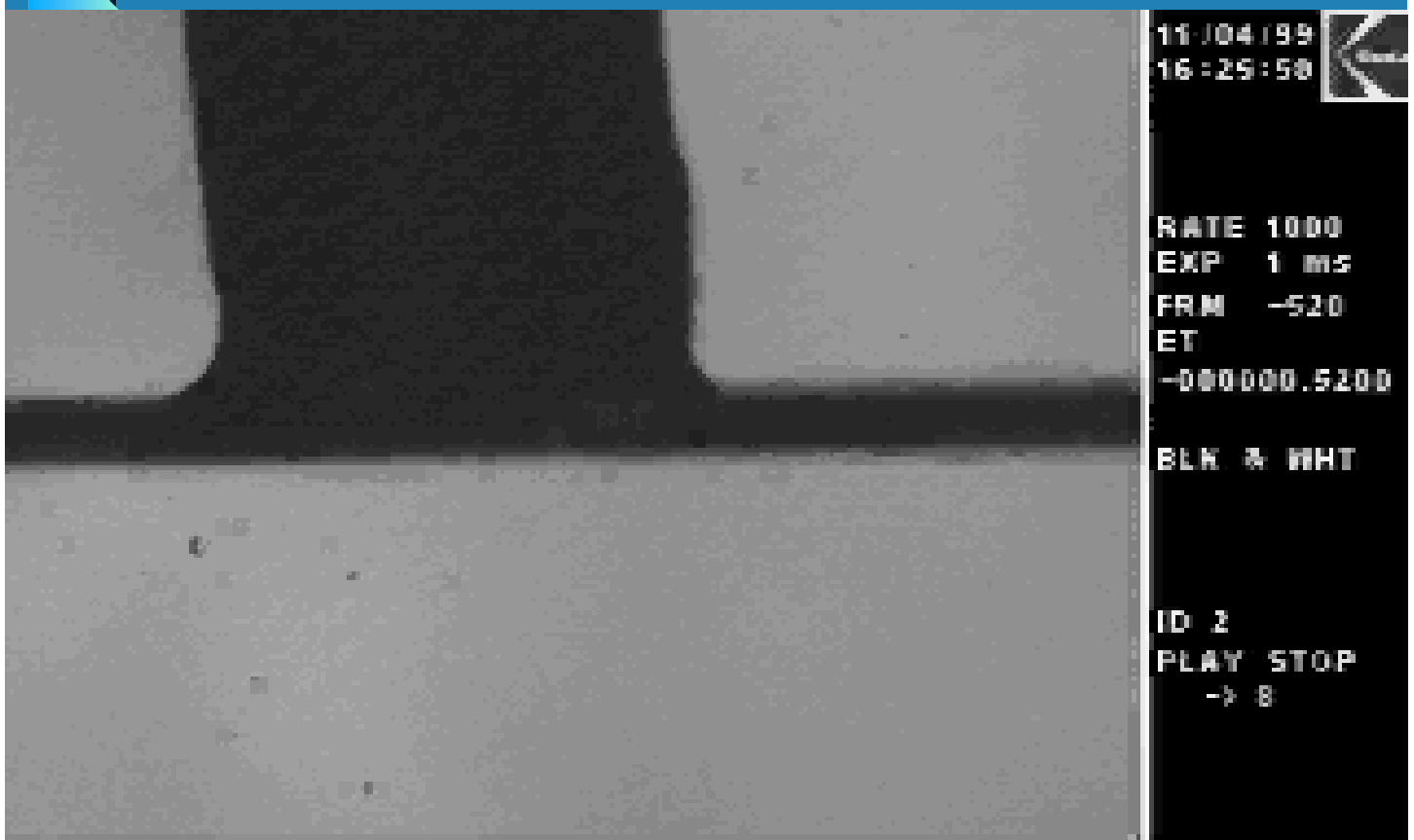
~1mm glass fiber + wax
Glass slide ~5x2x.15mm³
DI Water



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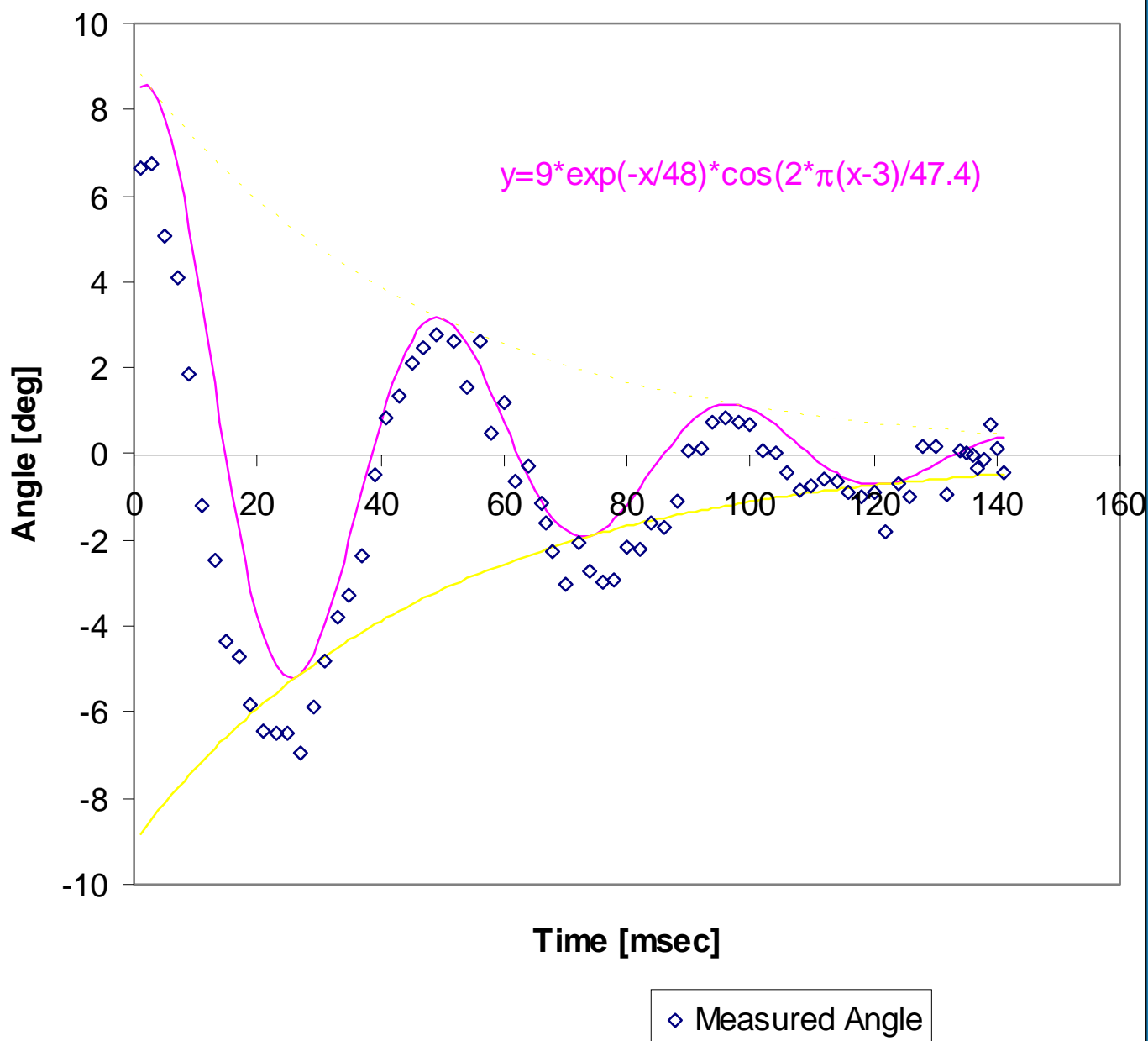
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Deflection Angle vs. Time

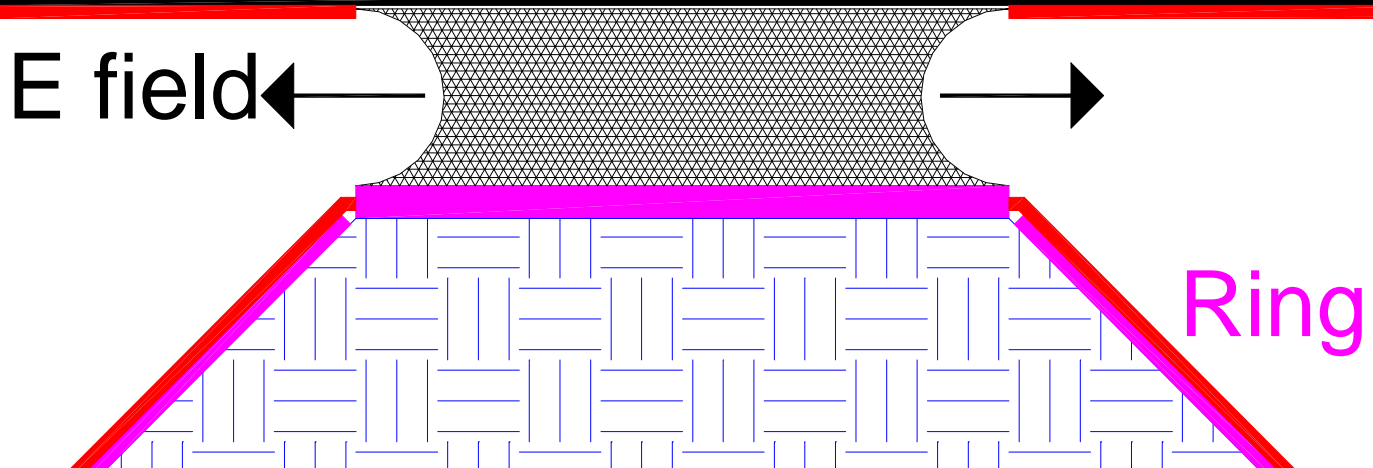


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Piston Motion

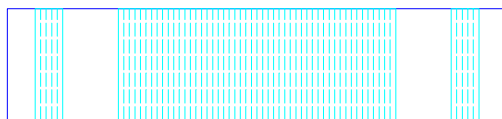
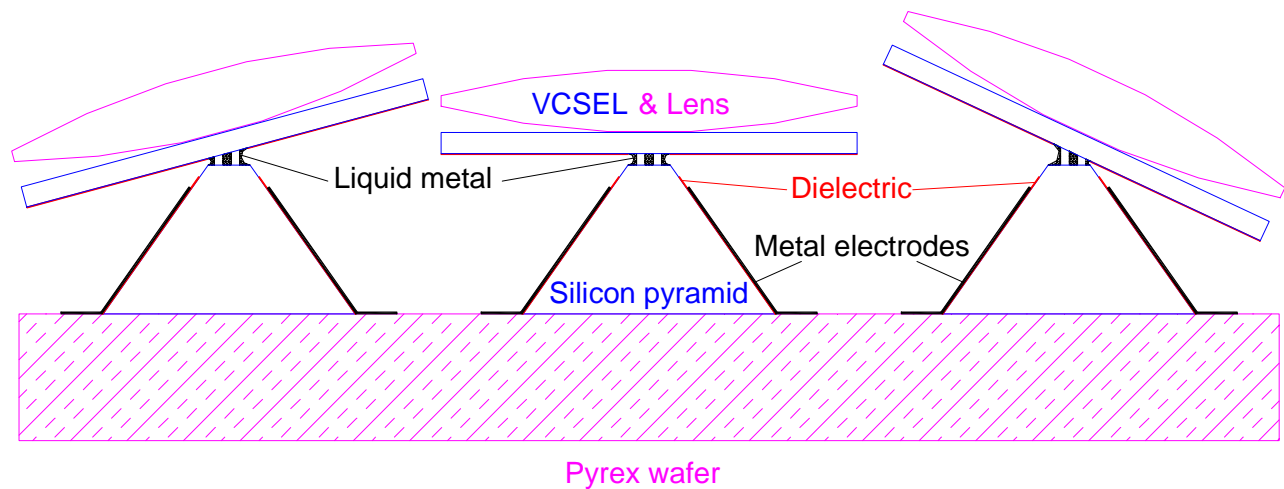


A potential applied between liquid and ring electrode will cause the liquid to creep out from under the mirror.

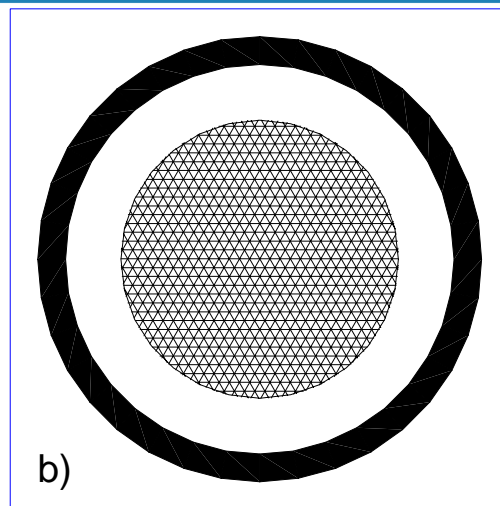
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Electrostatically Actuated VCSEL



a)

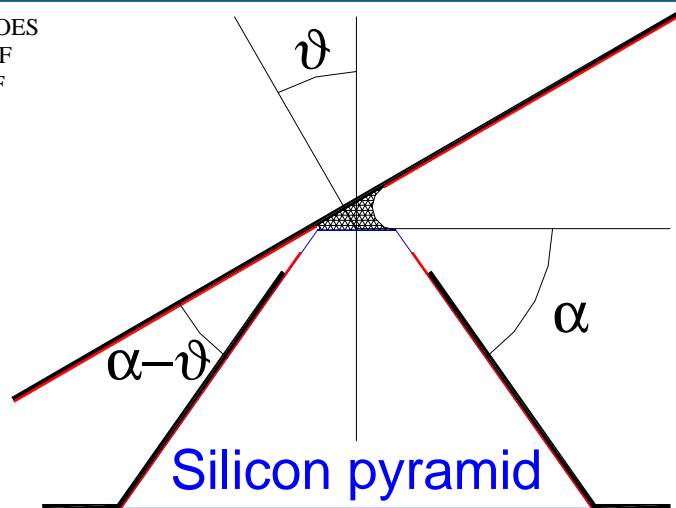


b)

Concentric liquid metal drop
provides electrical power to
moveable plate.

Torque vs. Angle from Surface Tension

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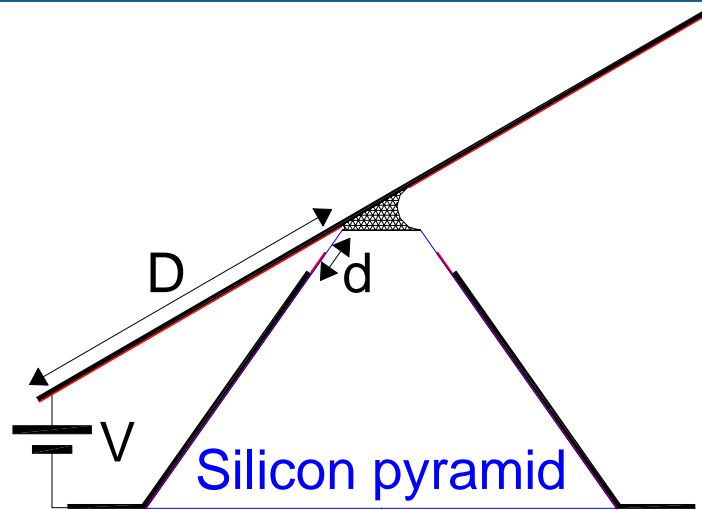


$$S(\theta) = 2L + (\pi - \theta)R_L(\theta) + (\pi + \theta)R_S(\theta)$$

$$S(\theta) \cong S(0) + C2 * \left(\frac{\theta}{2}\right)^2 + C4 * \left(\frac{\theta}{2}\right)^4$$

$$\Gamma_l(\theta) = -\gamma \frac{dS(\theta)}{d\theta} \approx -\frac{\gamma * C2 * \theta}{2}$$

Electrostatic Torque vs. Angle



$$E_{\theta}(r) = \frac{V}{r(\alpha - \theta)} \quad \sigma(r) = \frac{\epsilon_0 V}{r(\alpha - \theta)}$$

$$Q = \frac{\epsilon_0 V}{\alpha - \theta} \ln\left(\frac{D}{d}\right) \quad C(\theta) = \frac{\epsilon_0}{\alpha - \theta} \ln\left(\frac{D}{d}\right)$$

$$U(\theta) = -\frac{C(\theta)V^2}{2} = -\frac{\epsilon_0 V^2}{2(\alpha - \theta)} \ln\left(\frac{D}{d}\right)$$

Low Spring Constant for x-Area

- Liquid mercury,
 $\gamma \sim 0.51 \text{ N/m}$
- Drop $\sim 37\mu\text{m} \cdot 37\mu\text{m} \cdot 10\mu\text{m}$
- Spring constant
 $k \sim 0.5\gamma C^2 \sim 1.1 \text{ nNm}$
- Aluminum bar \sim
 $1\mu\text{m} \cdot 2\mu\text{m} \cdot 10\mu\text{m}$
- Spring constant
 $\sim 1.2 \text{ nNm}$

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Dynamics

$$I \frac{d^2 \theta}{dt^2} + \lambda \frac{d\theta}{dt} = k\theta$$

$$\omega = \sqrt{\frac{k}{I}} = \sqrt{\frac{\gamma 90 \times 10^{-6}}{mD^2}}$$

Formula predicts 250ms
period, movie ~40ms

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Dynamics

Reduce mirror size from
 $0.15 \cdot 2.5 \text{mm}^3$ and 3.5mg
to $0.02 \cdot 0.2 \cdot 0.2 \text{mm}^3$ and
 $7 \mu\text{g}$, period less than
 1ms

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Evaporation Rate

$$G := P_{\text{drop}} \cdot \left(\frac{M}{2 \cdot \pi \cdot R \cdot T_{\text{drop}}} \right)^{.5}$$

$$\tau := \frac{(.1 \cdot \text{Volume} \rho)}{G \cdot \pi \cdot L \cdot t}$$

$\tau(\text{Hg}) \sim 71 \cdot \text{s}$ since $P(\text{Hg})$
is $\sim 0.13 \text{ Pa}$ at 300K

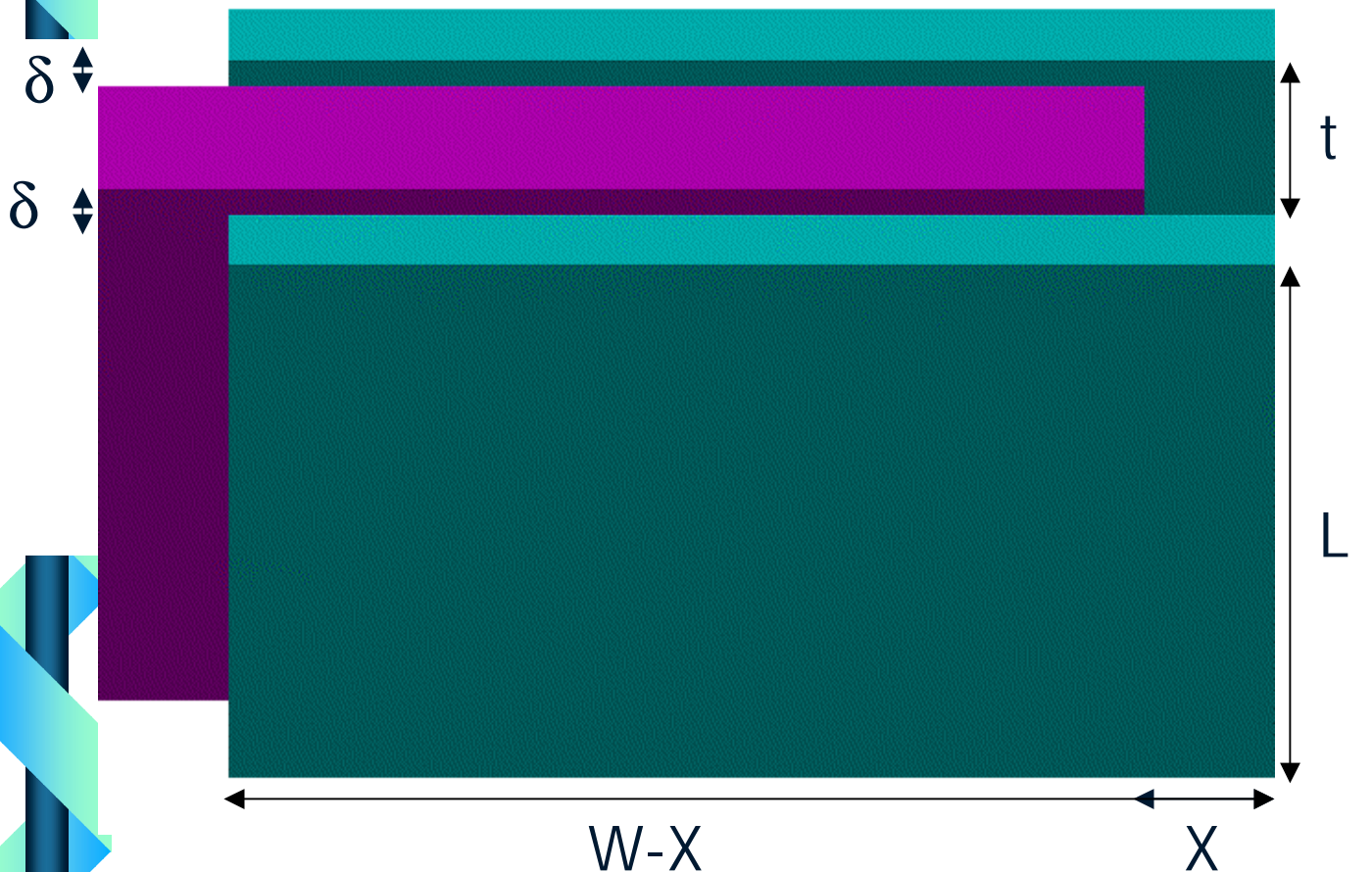
Micro-mirror Conclusions

- Stress free mirror mounting.
- Actuation about two axis.
- Piston motion possible.
- Random access time of Micro-mirror ~0.7msec for 0.2mm 7 μ g mirror.
- Two dimensional liquid and electrostatic analysis.

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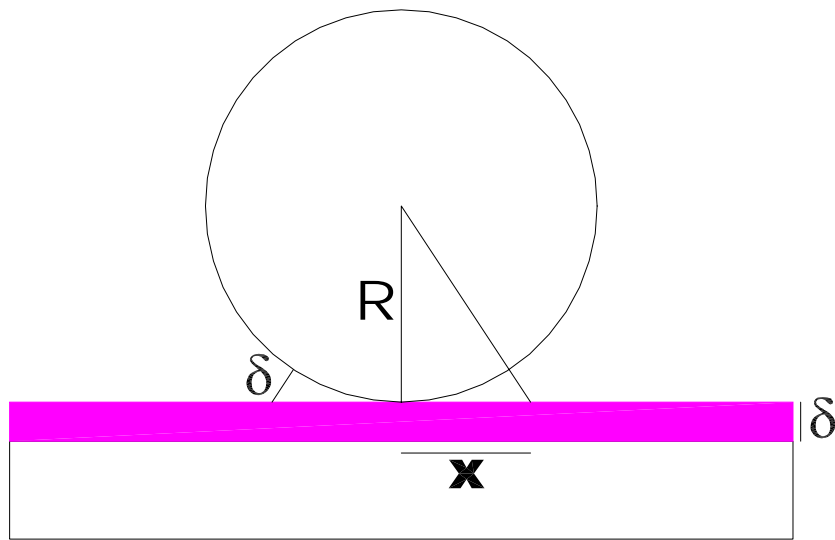
Variable Capacitor



$$t \gg \delta \quad F = - \frac{(\epsilon \epsilon_o L V^2)}{4\delta}$$

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Spherical Capacitor



$$R = 500\mu\text{m}, \quad \delta = 1\mu\text{m}$$

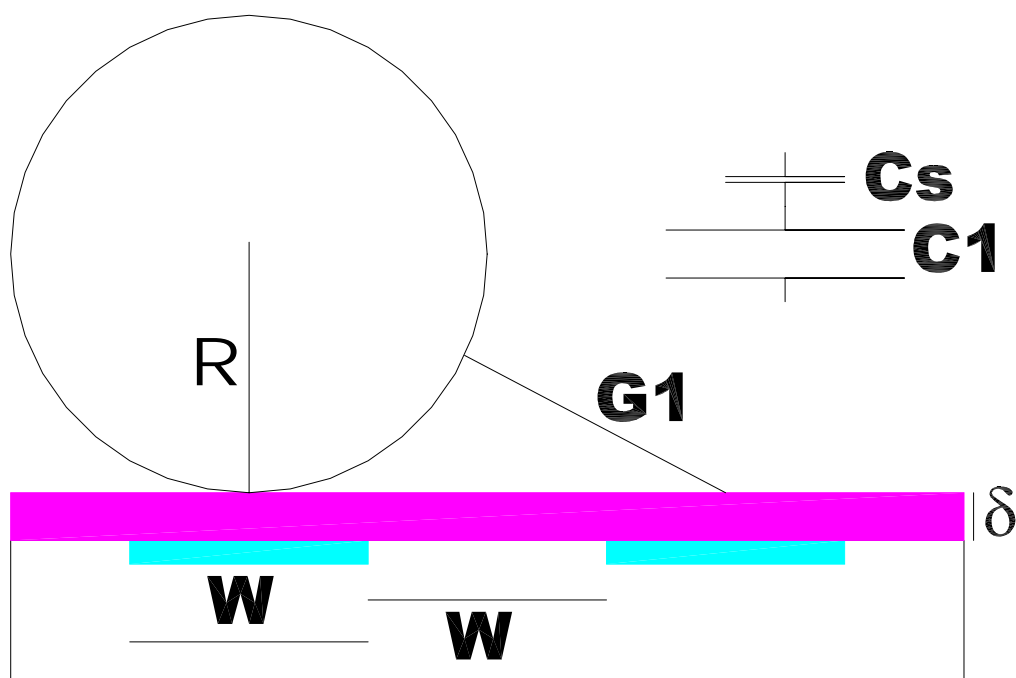
$$x = \sqrt{2R\delta} \quad x \cong 30\mu\text{m}$$

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Unstable position



$$C_{T1} = \frac{1}{\frac{1}{Cs} + \frac{1}{C1}} \cong C1 = \epsilon_o 2\pi R$$

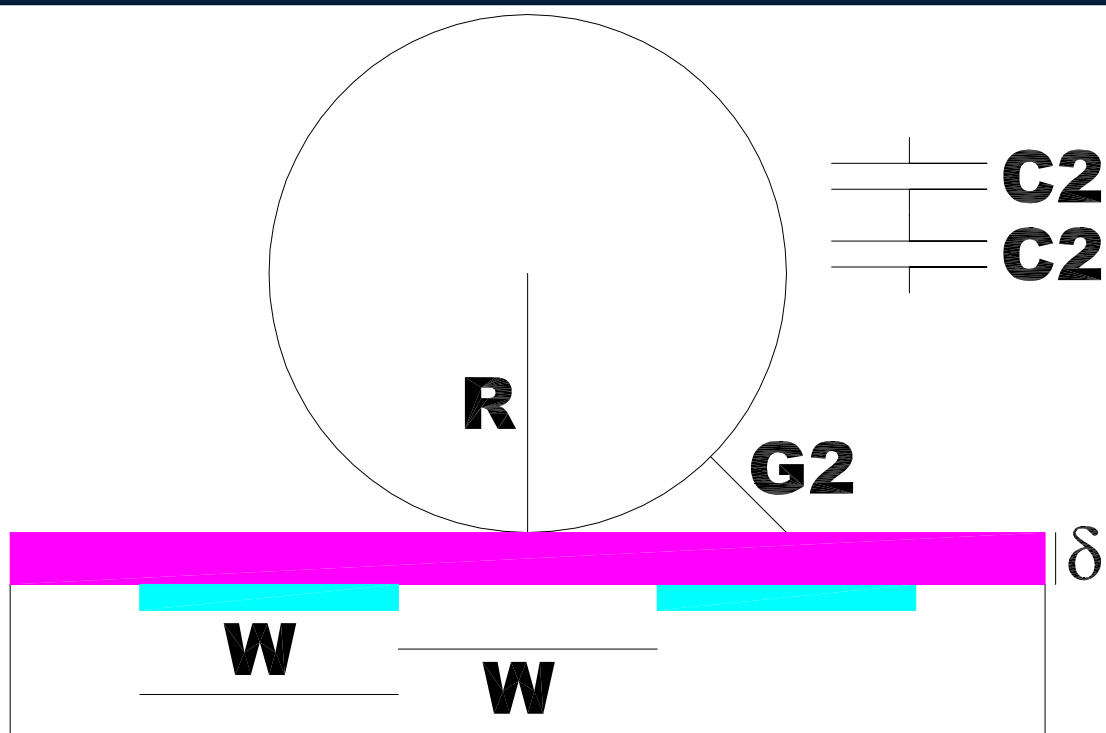
$$W = 100\mu m, G1 = 39\mu m \ll R$$

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Stable position



$$C_{T2} = \frac{C2}{2} = \epsilon_o \pi R$$

$$G2 = 10 \mu m \ll R$$

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Electrostatic Force

$$F_e \approx -\frac{\Delta U}{\Delta x} \approx -\frac{C1 * V^2}{4W} = 20\mu N, V = 500V$$



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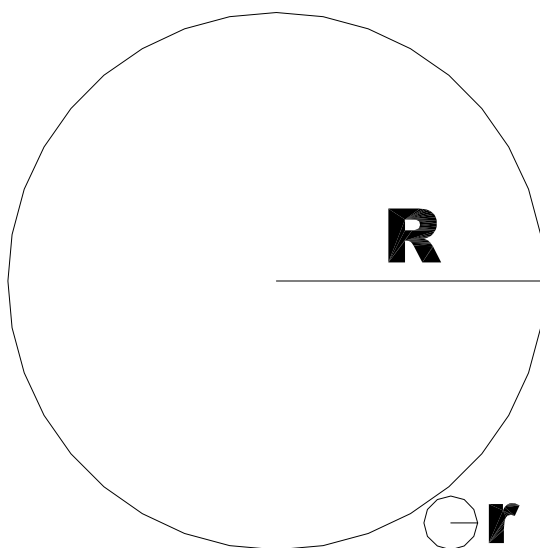


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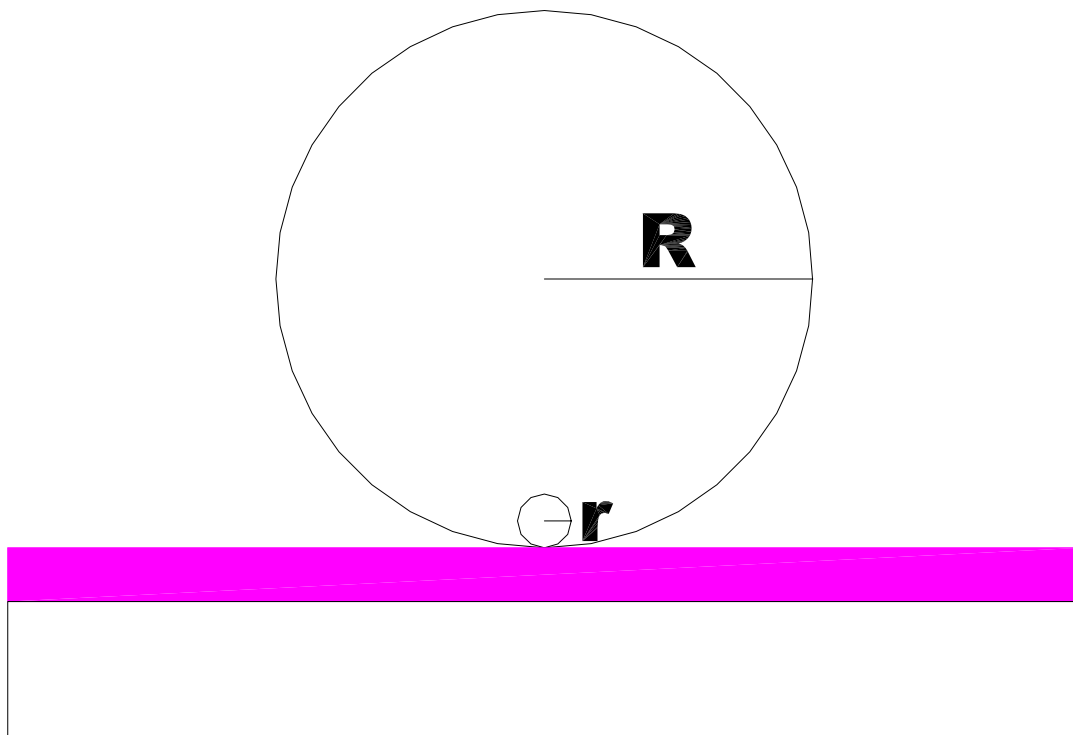
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Rolling over dust



$$F_h \approx -\frac{\Delta U}{\Delta x} \approx -\frac{\rho * \frac{4}{3}\pi R^3 * g * 2 * r}{R} = 2\mu N, r = 10\mu m$$

Surface Deformation



$$F_d \approx -\frac{\Delta U}{\Delta x} \approx -\frac{\sigma 4\pi r^2}{R} = 1\mu N, \sigma = .5 \frac{N}{m}$$